

**IN THE ABSTRACT OF THE DISCLOSURE:**

Please amend the Abstract of the Disclosure to read as follows:

In a legged mobile robot (10), each hip joint (~~18R, 18L~~) that connects a body (14) with a thigh link (~~16R, 16L~~) comprises a first rotary shaft (~~18RZ, 18LZ~~) that provides a degree of freedom to rotate about a yaw axis (~~Z-axis~~), a second rotary shaft (~~18RX, 18LX~~) that provides a degree of freedom to rotate about a roll axis (~~X-axis~~), and a third rotary shaft (~~18RY, 18LY~~) that provides a degree of freedom to rotate about a pitch axis (~~Y-axis~~), and in addition thereto, a fourth rotary shaft (~~18RR, 18LR~~) that provides a redundant degree of freedom. Owing to this configuration, the amount of body (14) bending and the movable range of the legs (~~12R, 12L~~) can be increased, thereby improving the degree of posture and gait freedom.